

FIG. 1 is a perspective view of a robotic arm assembly. The assembly includes a base link (11), a middle link (14), and an end effector link (13). The links are connected by revolute joints (12). Arrows indicate the degrees of freedom at the joints.

FIG. 1  
PRIOR ART

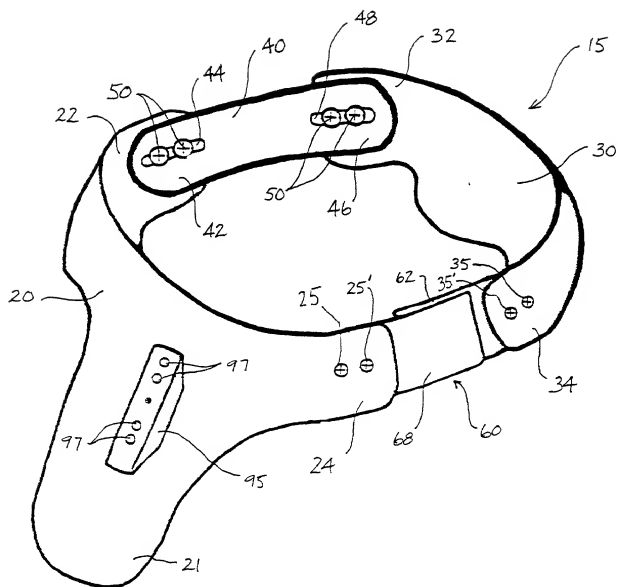


FIG. 2

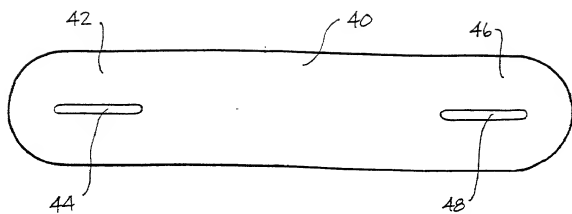


FIG. 3

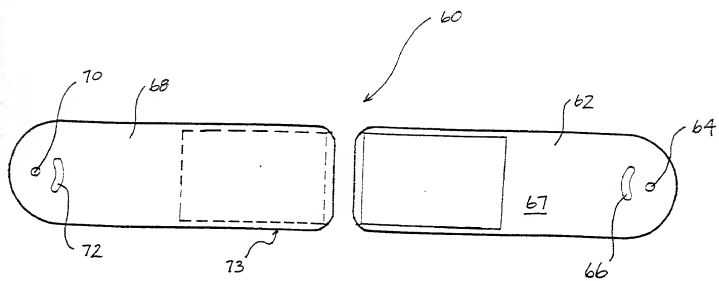


FIG. 4

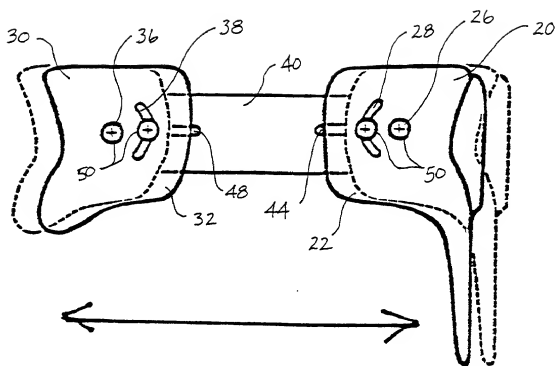


FIG. 5

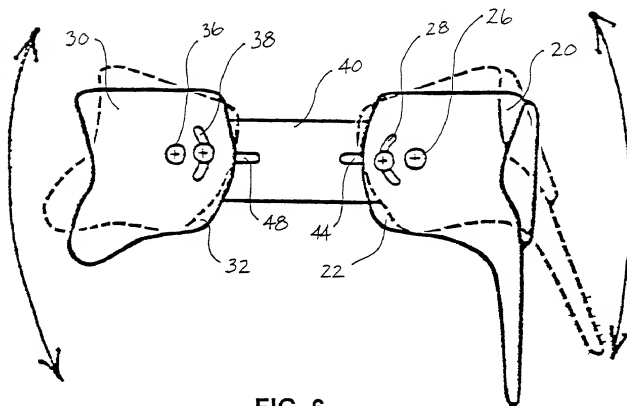


FIG. 6

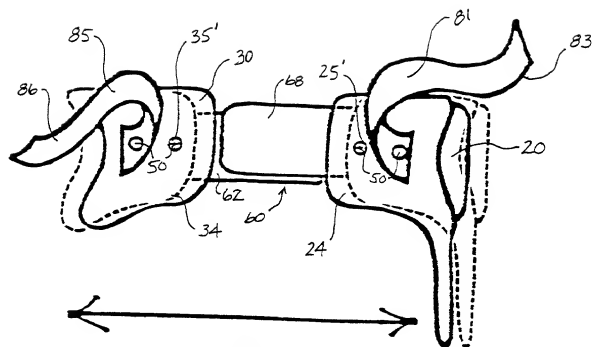


FIG. 7

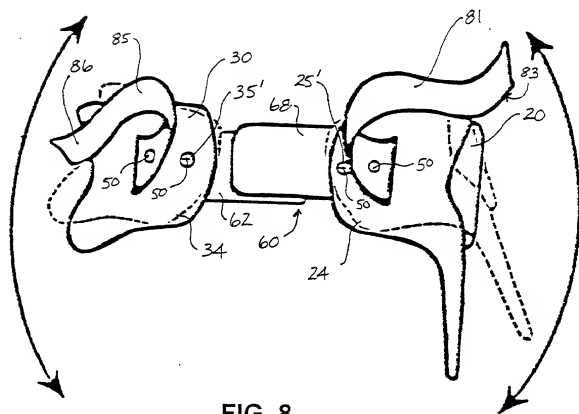


FIG. 8

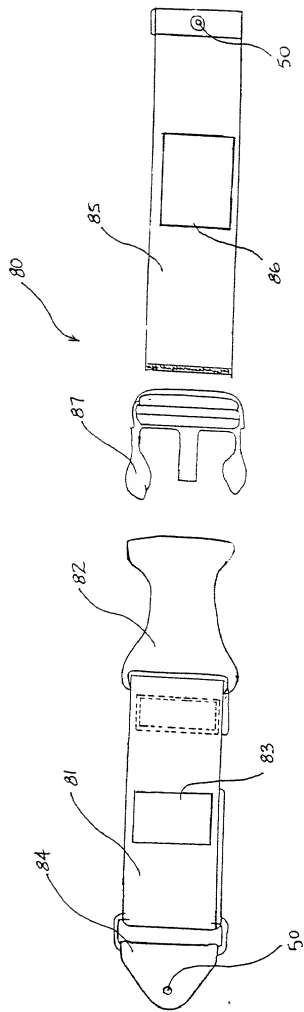


FIG. 9



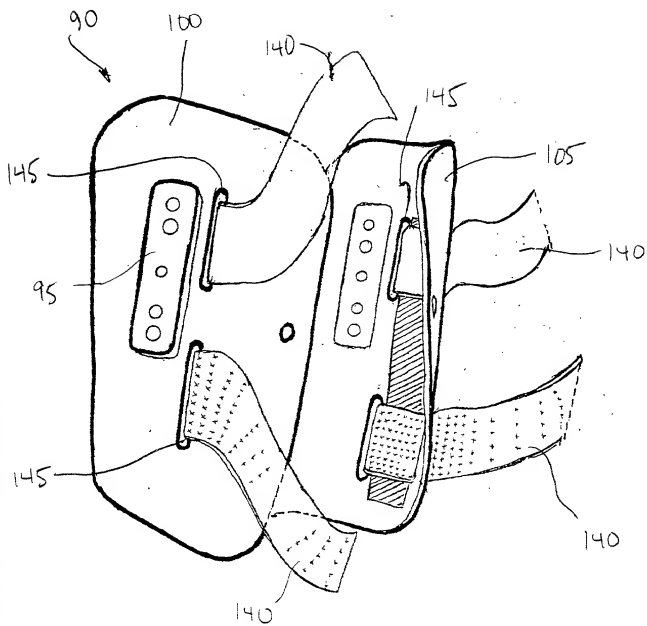


FIG. 15